

Real-time Operating Systems and Systems Programming

Introduction Lecture 1

About the Course

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Expectations

- Familiarity with C programming language
 - There will be a test on Oct 6
- Some familiarity with command-line helps

Test

- ♦ Oct 6.
- ♦ Devious puzzles
- ♦ Everything you can do without libraries
 - C keywords
 - Precedence
 - Pointers and arrays
- ♦ Goal is to brainwash you
 - Tricks your brain into remembering things
 - Gives extra points for the exam
- ♦ Feedback on general C proficiency

Extremely nasty C (test is easier)

```
typedef unsigned char B;char*x[]={
#include "dict.h"
0};typedef struct L{B*s;struct L*n;}L;
L*h[128],*l[128],*s[128],Z[sizeof x/sizeof*x],*F=Z;int c[256],m,a=1;
int k(B*q){int g=0;B*p=q;while(*p)g|=!c[*p++]--;return g-1&p-q;}
void u(B*p){while(*p)c[*p++]++;}
void S(int N,int r,int t,L*W){L*w;int i,n;
for(n=r<N?r:N;n>0;n--)for(w=n==N?W:h[n];s[t]=w;u(w->s),w=w->n)if(k(w->s))
if(n==r){if(t==m-1)for(i=a=0;i<=t;i++)printf("%s%c",s[i]->s,i<t?' ':'\n');}
else if(t<m-1)S(n,r-n,t+1,s[t]=w);}
int main(int C,B**A){int i=0,g,n=0;B*p;while(--C)for(p=*++A;n<127&&*p;)c[*p++]++,n++;
for(;p=x[i++];u(p))if(g=k(p))(l[g]=*(l[g]?&l[g]->n:&h[g])=F++)->s=p;
while(++m<128)S(127,n,0,h[127]);
return a;}
```

- Peter Klausler, IOCCC 2006 (<http://www.ioccc.org/>)

Grades

- Programming project(s) (40%)
 - Small practice tasks (show them!)
 - At least one larger program
- Exam (60%)
 - Terminology, some functions, code reading, coding on paper

Topics

- Hardware IO; interrupts
- Stack, heap
- Signals, threads, processes, mutexes
- Scheduling
- Standard IO, file, dir management
- Programming an Operating System
- Networking
- Optimizing, security, Localization

C keywords

- Types
 - char double enum float int long short struct union void
- Parameters to variables
 - auto const extern register signed static unsigned volatile
- Flow control
 - break case continue default do else for goto if return switch while
- Operators
 - sizeof, typeof

Operator precedence

```
>> ( ) [ ] -> .  
<< ! ~ ++ -- + - * & (type) sizeof  
>> * / %  
>> + -  
>> << >>  
>> < <= > >=  
>> == !=  
>> &  
>> ^  
>> |  
>> &&  
>> ||  
<< ? :  
<< = += -= *= /= %= &= ^= |= <<= >>=  
>> ,
```

Maths and Logic

```
(things I want done before maths)

>> *   /   %   (maths)
>> +   -

(things between maths & logic)

>> &
>> ^
>> |   (logic)
>> &&
>> ||

(things I want after logic)
```

Really important things

```
>> ( ) [] -> . {language constructs}
<< ! ~ ++ -- + - * & (type) sizeof {unary}
>> * / % {maths
>> + - }

>> & {logic
>> ^
>> |
>> &&
>> || }
```

What goes between maths and logic?

```
>> ( ) [ ] -> . {language constructs}
<< ! ~ ++ -- + - * & (type) sizeof {unary}
>> * / % {maths}
>> + - }

>> < <= > >= {comparison}
>> == != {equality}
>> & {logic}
>> ^
>> |
>> &&
>> || }
```

Finally

```
>> ( ) [ ] -> .  
<< ! ~ ++ -- + - * & (type) sizeof  
>> * / %  
>> + -  
>> << >>  
>> < <= > >=  
>> == !=  
>> &  
>> ^  
>> |  
>> &&  
>> ||  
<< ? :  
<< = += -= *= /= %= &= ^= |= <<= >>=  
>> ,
```

Variables

- Name to an address.
- Type says amount of memory to reserve
- Must be declared before use

Some reading

- ♦ Main books:
 - Brian W. Kernighan, Dennis M. Ritchie *The C Programming Language, Second Edition*, Prentice Hall 1988
 - Randal E. Bryant and David R. O'Hallaron *Computer Systems: A Programmer's Perspective (CS:APP)*, Prentice Hall, 2003
 - *Note: also has a newer edition*

Real-Time Systems

- Hardware or software which has a time constraint for reactions
- For our purposes, also embedded systems
 - What would be the difference?

Characteristics

- Specified limit on system response latency
- Event-driven scheduling
- Low-level programming
- Software coupled to special hardware
- Volatile Data
- Multi-tasking implementation
- Unpredictable environment
- Runs continuously
- Life-critical applications

Example: Anti-lock brakes

- Must prevent locking of wheels while braking
- Inputs: Brake pedal, Wheel rotation
- Actuators: Brakes

Human brain?

- "The human brain runs a Real-Time Operating System. Conscious thought is a low priority task."
 - Bob Cross on c2 wiki
- Real-time system or not?

Pathfinder Rover

- Initially successful: July 4, 1997
- Software resets start
 - Serious data losses
 - Problem: bus overloaded with data
 - Low priority data collection locks the bus, medium priority tasks interrupt it
 - High priority data distribution task fails: cannot get bus
 - Scheduler detects pending high-priority task & resets

Solutions

- Priority inversion: high priority task delayed in a critical section by low priority tasks
- Solution was priority inheritance: low priority tasks entering critical section will inherit the highest priority of waiting tasks
- Solved the Pathfinder reset problem

More examples

- Microwave, dishwasher, toaster
- Cars: cruise control, drive-by-wire
- Computers: peripheral devices, applications
- Planes: auto-pilot, stability, fly-by-wire

Terminology

- System: black box with n inputs and m outputs
- Response time: time between presentation of a set of inputs and the appearance of the corresponding outputs
- Events: Changes of state which cause changes in flow-of-control of a program
 - Synchronous: events occur at predictable times
 - Asynchronous: events interrupt flow-of-control

State vs Event based

- State based:
 - System constantly reads system inputs and reacts to their combination
- Event based
 - System is in standby and events “wake” it to make it work

Deterministic RTS

- A deterministic RTS: you can determine a unique set of outputs and next state from a given set of possible states and inputs.

Real time Correctness

- Correctness depends on result and the time of delivery.
- Soft – missing some deadlines not a problem
- Firm – missing deadline: result worthless, but not a problem
- Hard – missing a deadline makes result worthless and is a problem

Misconceptions

- “Really fast” is real-time.
 - Might not be predictable enough
- Interactive is real-time.
 - Again: interactive optimized for “average” case.
- Real-time = “Bug free”:
 - Often the case, but bug free is wider concept

Static Predictability

- RT system: satisfying time constraints
 - Assumptions about workload and sufficient resources
 - Certified at design time, that all constraints will be met
- For static systems, 100% guarantees can be given at design time
 - Requires immutable workload and system resources
 - System must be re-certified on any change

Dynamic Predictability

- Dynamic systems: not statically defined
 - Systems configurations might change
 - Workload might change
- Dynamic predictability
 - Under appropriate assumptions (sufficient resources)
 - Tasks will satisfy time constraints

Latency minimization

- Latency is the time between an event and the system's reaction to it.
- We want to minimize latencies
 - For different applications, different latencies are required.
 - 10 ms might be barely enough (probably a dedicated system)
 - 500 ms might be enough (we could use an external kernel)

Multiple Requirements

- Real-time
- Power constraints
- Size constraints
- Cost limits
- Security requirements
- Fault tolerance
- *Often conflicting*

New Environments

- Ubiquitous Computing
 - Computers become invisible, so embedded and natural that we use them without thinking of using them.
- Autonomous Computing
 - Self-configurable
 - Self-adapting
 - Optimizing
 - Self-healing

End of buzzwords

- Lab: Linux environment and command-line and hello world
- Send an e-mail to jaagup.irve@ttu.ee with your name so there will be a log of you being here